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| --- | --- |
| **Accuracy** |  |
| For the older version of the project, your algorithm will be run against "sample-laser-radar-measurement-data-1.txt". We'll collect the positions that your algorithm outputs and compare them to ground truth data. Your px, py, vx, and vy RMSE should be less than or equal to the values [0.09, 0.09, 0.65, 0.65]. |  |
| For the older version, your algorithm will also be run against "sample-laser-radar-measurement-data-2.txt". The RMSE for the second data set should be <=[0.20, 0.20, 0.55, 0.55]. |  |
| **Follows the Correct Algorithm** |  |
| Your Sensor Fusion algorithm follows the general processing flow as taught in the preceding lessons. | Implemented most of the code from lesson quizzes |
| Your Kalman Filter algorithm handles the first measurements appropriately. | Between 106 - 147 |
| Your Kalman Filter algorithm first predicts then updates. | Between lines 149 - 494 |
| Your Kalman Filter can handle radar and lidar measurements. | Both used |